

EAST Search History

EAST Search History (Prior Art)

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
L1	12	("20020159628" "4,942,539" "5,802,201" "20040233461" "20100040255" "20010034481").pn.	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:06
L2	317	pose near0 estimation and three near2 dimensional and two near2 dimensional	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:22
L3	40	pose near0 estimation and three near2 dimensional and two near2 dimensional and target near0 object	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:23

L4	14	("20020159628" "4,942,539" "5,802,201" "20040233461" "20100040255" "20010034481" "4,729,536").pn.	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:54
L5	0	camera near0 mounted same movable same portion and robot near5 effector	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:58
L6	1	camera near0 mounted same movable same portion same robot	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:59
L7	38	camera near0 mounted and movable same portion same robot	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 11:00

L8	1	camera near3 mounted near5 orthogonally same robot	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 12:54
L9	4	camera near6 orthogonally same robot	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 12:55
L10	5	camera near10 orthogonally same robot	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 12:55
L11	16	camera near10 orthogonally and robot	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 12:56

L12	14	camera same orthogonally same robot	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 13:02
L13	115	camera same orthogonally and robot	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 13:12
L14	27	adjusting near3 position same robot and insufficient and image and target and object	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 14:10
S1	0	digital near0 cameara and extrinsic near0 parameters	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:46

S2	0	cameara and extrinsic near0 parameters	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:47
S3	670	extrinsic near0 parameters	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:47
S4	494	extrinsic near0 parameters and camera	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:47
S5	249	extrinsic near0 parameters and camera and image near10 calibration	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:48

S6	56	extrinsic near0 parameters and camera and image near10 calibration near0 object	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 12:44
S7	4102	robot and manipulate and scal\$3	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 13:04
S8	6	extrinsic near0 parameters and camera and image near10 calibration near0 object and S7	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 13:05
S9	56	extrinsic near0 parameters and camera and image near10 calibration near0 object	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 14:54

S10	1917	robot and manipulate and scal\$3 and sample and features	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 14:56
S11	152	robot and manipulate and scal\$3 and sample and features and reference near0 frame	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 15:01
S12	34	robot same manipulate and scal\$3 and sample and features and reference near0 frame	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 15:32
S13	31	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 15:39

S14	24	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulat\$3 and frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 16:15
S15	16	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulat\$3 and frame and six	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 16:20
S16	6	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulat\$3 and frame and six and camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 17:09

S17	6	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulat\$3 and frame and six and camera and position and frame	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 17:18
S18	6	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulat\$3 and frame and six and camera and position and frame and computer	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 17:48

S19	8168	(700/245 1700/246 1700/253 1700/257 1700/258 1700/259 1700/279 or 29/218 129/702 129/714 129/720 129/407.1 129/407.04 or 318/568.13 318/568.15 1318/568.16 1318/640 or 348/42 1348/94 1348/154 1348/1901 348/291 1348/287552 or 901/6 1901/14 1901/17 1901/46 1901/47 or 414/730 1414/737 or 382/154). ccls.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 20:52
S20	117	("4871252" or "5999881" or "4949277" or "4980762" or "5016110" or "5177563" or "5295778" or "5300869" or H001378 or "5696674" or "5819304" or	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 20:54

"5870303" or
"6081370" or
"6096999" or
"4273505" or
"4299386" or
"4307891" or
"4312432" or
"4359815" or
"4421450" or
"4479754" or
"4479717" or
"4480170" or
"4484855" or
"4488173" or
"4494874" or
"4502830" or
"4556360" or
"4568238" or
"4574655" or
"4576537" or
"4582277" or
"4594001" or
"4624621" or
"4627511" or
"4762459" or
"4764077" or
"4779804" or
"4782567" or

		"4783904" or "4789417" or "4815901" or "4818858" or "4865514" or "4875273" or "4875823" or "4886375" or "4934504" or "4942539" or "4943889").pn.				
S21	961	camera and orthogonal near0 axes and rotation and translation	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 08:53
S22	171	camera and orthogonal near0 axes and rotation and translation and reference near0 frame	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 08:53

S23	0	camera and orthogonal near0 axes and rotation and translation and reference near0 frame and space near6 training	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 08:54
S24	23	camera and orthogonal near0 axes and rotation and translation and reference near0 frame and space and training	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 08:54
S25	209	scale near0 factor and framegrabber	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:11
S26	2	scale near0 factor same framegrabber	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:11

S27	2	scale near0 factor same framegrabber and resampling	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:12
S28	0	scale near0 factor same framegrabber and sampling	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:12
S29	2	scale near0 factor same framegrabber and focal near0 length	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:13
S30	2	scale near0 factor same framegrabber and camera	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:13

S31	2	scale near0 factor same framegrabber and lens	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:13
S32	2	scale near0 factor same framegrabber and distortion	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:14
S33	354	object near0 space near0 coordinate	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:51
S34	3	object near0 space near0 coordinate and select\$3 near0 feature	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:52

S35	60	object near0 space near0 coordinate and image and teaching	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:53
S36	30	object near0 space near0 coordinate and select\$3 near10 image and teaching	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 11:00
S38	0	robot same mov\$3 near3 camera near0 orthogonally	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:39
S39	1	robot same mov\$3 near10 camera near0 orthogonally	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:39

S40	0	robot same mov10 near10 camera near0 orthogonally	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:39
S41	0	robot same orient\$3 near10 camera near0 orthogonally	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:40
S42	0	robot same camera near0 orthogonally	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:40
S43	24	camera near0 orthogonally	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:41

S44	0	camera near0 orthogonally and robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:41
S45	2	camera and object near0 space near0 reference near0 frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:05
S46	80	camera and object near6 space near10 reference near0 frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:06
S47	56	camera and object near6 space near5 reference near0 frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:06

S48	0	("20020159628" "4,942,539" "5,802,201" "20040233461" "20100040255" "20010034481").pn. and position near3 orientation and tool near0 frame near0 reference and transformations	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:58
S49	13	position near3 orientation and tool near0 frame near0 reference and transformations	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:58
S50	12	position near3 orientation and tool near0 frame near0 reference and transformations and object	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:59

S51	2	"20100231706".pn.	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 23:15
S52	1	"20100231706".pn. and tool	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 23:15
S53	0	adjusting same robot same insufficient and image and target near0 object	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:04
S54	2	adjusting same robot same insufficient and image and target and object	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:04

S55	2	adjusting same robot same insufficient and image	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:05
S56	139	adjusting same robot and insufficient and image	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:06
S57	104	adjusting same robot and insufficient and image and target	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:06
S58	103	adjusting same robot and insufficient and image and target and object	US_PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:06

EAST Search History (Interference)

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11/26/10 2:18:58 PM

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